

In the Claims:

Please amend Claim 6 as follows in "clean" format:

92 ~~6. A controller for an active steering system, the controller comprising:~~  
a feel control algorithm for controlling a feel back torque to a driver, said feel control algorithm comprising a filter, and at least one of a high-pass gain and a low-pass gain; wherein at least one of said high-pass gain and said low-pass gain correspond to at least one of an error signal and a low-pass portion of the error signal.

Please amend Claim 12 as follows in "clean" format:

93 ~~12. A controller as defined in Claim 6 wherein said filter is a first-order filter.~~

Please amend Claim 14 as follows in "clean" format:

94 ~~14. A method for actively controlling the steering of a motor vehicle, the method comprising:~~  
receiving an operator input from an operator of the motor vehicle,  
receiving a stability input indicative of a dynamic stability of the motor vehicle;  
calculating a correction signal in accordance with the operator input and the stability input;  
filtering the correction signal into a plurality of frequency bands;  
applying a gain to at least one of the filtered bands to produce an output signal corresponding to a desired feel back torque; and  
adjusting an input to a differential actuator in accordance with the output signal.

Please amend Claim 23 as follows in "clean" format:

95 ~~23. An active steering system as defined in Claim 22 wherein said feel controller further comprises a summing function for receiving an input of the low-pass filter and an output of the low-pass filter, and for providing an input to a high-pass gain function.~~

Please amend Claim 26 as follows in "clean" format:

Please amend Claim 26 as follows in "clean" format:

26. ~~An active steering system comprising:~~  
means for receiving a steering input from an operator of the motor vehicle;  
means for receiving a stability input indicative of a dynamic stability of the  
motor vehicle;  
means for calculating a correction signal in accordance with the steering input  
and the stability input;  
means for filtering the correction signal into a plurality of frequency bands;  
means for applying a gain to at least one of the filtered bands to produce an  
output signal corresponding to a desired feel-back torque; and  
means for adjusting an input to a differential actuator in accordance with the  
output signal.

Please amend Claim 27 as follows in "clean" format:

27. ~~A motor controller, comprising:~~  
a feel control algorithm for controlling a feel back torque to an operator, said  
feel control algorithm comprising a filter, and at least one of a high-pass gain and a low-pass  
gain;  
wherein at least one of said high-pass gain and said low-pass gain correspond  
to at least one of an error signal and a low-pass portion of the error signal.